AMENDMENTS TO THE CLAIMS

Please amend claims 40, 43-46, 48, 51, 54, 56, 57, 59, 62, 64 and 72 as follows.

Please cancel claims 42, 50, 52, 53, 60, 68 and 69 without prejudice.

This listing of claims below will replace all prior versions, and listings, of claims in the application.

1-39. Listing of Claims:(Cancelled)

40. (**Currently amended**) An automated positioning system for determining [[the]] an angular ~~position~~ deviation of a vehicle from ~~with respect to~~ a predetermined path, ~~using at least two beams sweeping across at least a sector of interest said at least two beams originating from a known position relative to the predetermined path,~~ the system comprising:

~~at least one~~ an electro-optical sensor onboard the vehicle for detecting [[said]] ~~at least~~ two beams that scan across at least a sector of interest in opposite directions and that are synchronized with each-other so as to substantially overlap in the direction of the predetermined path, said two beams originating from known positions relative to the predetermined path; and

a logic circuitry on board the vehicle for determining a difference in time of detection of said two beams, the difference in time being indicative of the angular deviation ~~processing a signal generated by said at least one electro-optical sensor so as to determine an angular position of the vehicle with respect to the predetermined path~~.

41. (Previously presented) The system as claimed in claim 40, wherein the logic circuitry comprises a processor.

42. (Cancelled)

43. (**Currently amended**) The system as claimed in claim 40, wherein the logic circuitry is configured to determine a ~~sweeping~~ scanning direction of a beam of said at least two beams across the sensor.

44. (**Currently amended**) The system as claimed in claim 40, wherein ~~said at least one~~ the electro-optical sensor comprises two sensing elements.

45. (**Currently amended**) The system as claimed in claim 40, wherein ~~said at least one~~ the electro-optical sensor is configured to distinctly detect an ~~different~~ optical characteristic ~~characteristics~~ of a beam of said ~~at least~~ two beams.

46. (**Currently amended**) The system as claimed in claim 40, wherein ~~said at least one~~ the electro-optical sensor is provided with a filter.

47. (Previously presented) The system as claimed in claim 46, wherein said filter is selected from a group consisting of: polarizing filter, wavelength filter.

48. (**Currently amended**) The system as claimed in claim 40, further comprising at least one off board beacon ~~located at the known position~~ for generating said ~~at least~~ two beams and wherein said known positions coincide.

49. (Previously presented) The system as claimed in claim 40, wherein a beam of said at least two beams sweeps back and forth across the sector.

50. (**Cancelled**)

51. (**Currently amended**) The system as claimed in claim 48, wherein said at least one beacon comprises two beacons each for generating a beam of said at least two beams.

52-53. (**Cancelled**)

54. (**Currently amended**) The system as claimed in claim 40, wherein said ~~at least~~ two beams are characterized by optical characteristics so as to allow determining of the ~~sweeping~~ scanning direction or azimuth information associated with each beam.

55. (Previously presented) The system as claimed in claim 54, wherein the optical characteristics are selected from a group of optical characteristics: polarization, wavelength, intensity, amplitude modulation frequency, amplitude modulation contrast.

56. **(Currently amended)** The system as claimed in claim 40, further comprising ~~wherein~~ a beam ~~of said at least two beams~~ that is characterized as spanning the entire sector and by ~~distinct~~ an optical ~~characteristics~~ characteristic that is spatially modulated so as to encode angular information ~~of specific angular zones~~ of that beam.

57. **(Currently amended)** The system of claim 40, wherein the logic circuitry is further ~~capable of generating~~ configured to control commands for controlling maneuvering actuators of the vehicle.

58. (Previously presented) The system of claim 40, wherein the vehicle is selected from a group consisting of: an unmanned aerial vehicle, a naval vessel, a land vehicle.

59. **(Currently amended)** An automated positioning method for determining an angular deviation ~~position~~ of a vehicle from ~~with respect to~~ a predetermined path, using ~~at least~~ two beams sweeping across at least a sector of interest in opposite directions and being synchronized so as to substantially overlap in the direction of the predetermined path, each beam of said two beams originating from a known position relative to the predetermined path, the method comprising:

detecting ~~at least one of said at least two beams,~~ by ~~at least one~~ an electro-optical sensor onboard the vehicle of said two beams; and

processing by a logic circuitry on board the vehicle of ~~a signal~~ signals generated by the sensor so as to determine a difference in time of detection of said two beams and processing the difference so as to determine the angular deviation ~~position~~.

60. (Cancelled)

61. (Previously presented) The method as claimed in claim 59, comprising determining a sweeping direction of a beam of said at least two beams across the sensor.

62. (**Currently amended**) The method as claimed in claim 61, wherein ~~said at least one~~ the sensor comprises two sensing elements.

63. (Previously presented) The method as claimed in claim 59, comprising distinctly detecting different optical characteristics of a beam of said at least two beams.

64. (**Currently amended**) The method as claimed in claim 59, further comprising providing at least one off board beacon ~~located at the known position~~ for generating said at least two beams.

65. (Previously presented) The method as claimed in claim 64, comprising generating by said at least one beacon a beam of said at least two beams such that the beam sweeps back and forth across the sector.

66. (Previously presented) The method as claimed in claim 64, wherein said at least one beacon comprises a single beacon.

67. (Previously presented) The method as claimed in claim 64, wherein said at least one beacon comprises two beacons.

68-69. (**Cancelled**)

70. (Previously presented) The method as claimed in claim 59, comprising characterizing a beam of said at least two beams by optical characteristics so as to allow determining of a sweeping direction or azimuth associated with the beam.

71. (Previously presented) The method as claimed in claim 70, wherein the optical characteristics are selected from a group of optical characteristics: polarization, wavelength, intensity, amplitude modulation frequency, amplitude modulation contrast.

72. (**Currently amended**) The method as claimed in claim 59, wherein a beam of said at least two beams is characterized as spanning the entire sector and by ~~distinct~~ an optical

~~characteristics~~ characteristic that is spatially modulated so as to encode angular information ~~of specific angular zones~~ of that beam..

73. (Previously presented) The method of claim 59, comprising generating control commands by the logic circuitry for controlling the maneuvering actuators of the vehicle.

74. (Previously presented) The method of claim 59, wherein the vehicle is selected from a group consisting of: an unmanned aerial vehicle, a naval vessel, a land vehicle.